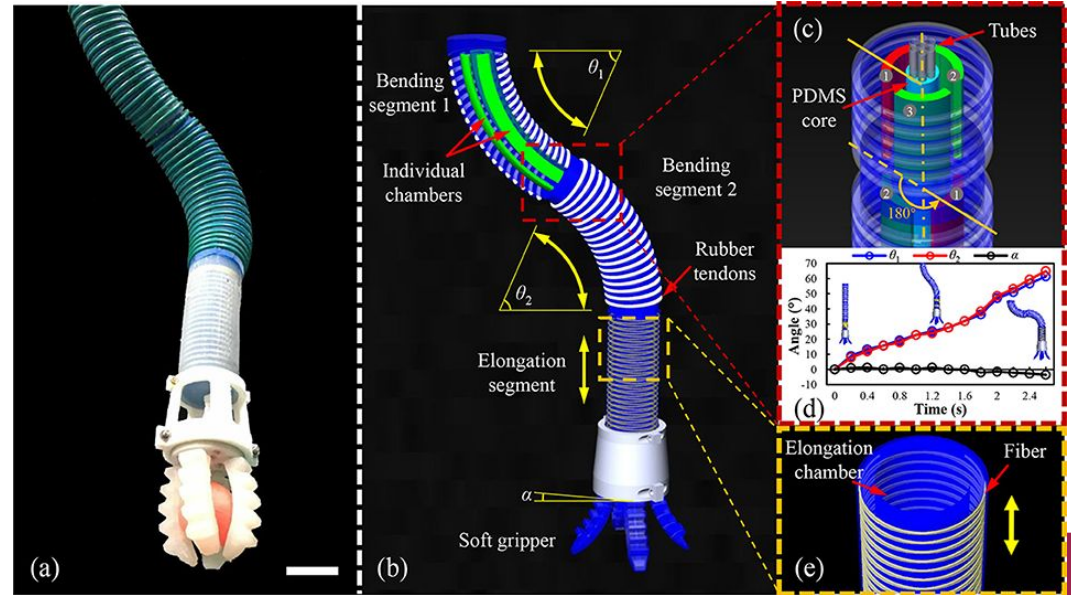# Project Proposal Presentation

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Idea

- Soft robot manipulator that is controlled via the first node
- Pros:
  - Increase maneuverability
- Cons:
  - Harder to control

Simulation Methodology

- Model the robot body as a discrete elastic rod
- The first node will be controlled via input (x_c, y_c, theta_c)
- The target node will be the last node and will track a certain trajectory / reach a certain position
- Newmark-Beta method to remove numerical damping